Abstract

A walk controller (30) to drive-control drive means of respective joint portions (15L, 15R to 20L, 20R) of respective leg portions (13L, 13R) based on gait data comprises force sensors (23L, 23R) to detect forces applied to the soles of respective foot portions(14L, 14R), and a compensation part (32) to adjust the gait data from a gait forming part (24) based on horizontal floor reaction force among the forces detected by the force sensors, respective force sensor parts (23L, 23R) comprises 3-axis force sensors (36a to 36d) provided to respective parts of soles divided into a plurality at respective foot portions (14L, 14R), a contact detection part (32b) detects a contact of foot sides by the force sensors provided to regions next to end edges of respective soles, and the compensation part (32) adjusts the gait data from the gait forming part (24) referring to the contact of foot sides, and thereby the contact of foot sides to such a matter as an obstacle is detected, and a walk stability is realized.